

What is claimed is:

1. An information processor comprising:
detecting means for detecting a multiplicity
of combinations of n parameter values, where n is
5 a natural number, for each of a plurality of operation
modes in which an object functions, which values
vary with operation; and

Self-Organizing Map creating means for
creating a Self-Organizing Map by using detection
10 data, obtained on the basis of the multiple
combinations of parameter values detected by said
detecting means, as learning data;

wherein said Self-Organizing Map creating
means creates a plurality of the Self-Organizing
15 Maps, serving as individual separation models and
corresponding one to each of the plurality of
operation modes.

2. An information processor according to
claim 1, wherein the detection data is
20 $2n$ -dimensional data including the n parameter values,
which have been detected and which indicate a
momentary state of the object, and n values that
are obtained by differentiating the n parameter
values which have been detected with respect to time
25 and that indicate a variation in the momentary state

of the object.

3. An information processor according to claim 2, wherein

said detecting means detects the multiple
5 combinations of n parameter values; and

said Self-Organizing Map creating means
initially arranges a predetermined number of neurons
at random in a $2n$ -dimensional space, carries out
training regarding a point of the detection data
10 in the $2n$ -dimensional space as a learning data point,
creates a Self-Organizing Map candidate regarding
a neuron having a minimum distance to the learning
data point as a winning neuron, and selects, from
two or more of the Self-Organizing Map candidates
15 obtained by carrying out the creating of a
Self-Organizing Map candidate a number of times,
a Self-Organizing Map candidate which has a
characteristic closest to that of the learning data
as the Self-Organizing Map.

20 4. An information processor according to
claim 3, said Self-Organizing Map creating means
calculates an average of distances of the winning
neurons to the points in the learning data and a
standard deviation of the distances of the winning
25 neurons to the points in the learning data for each

of the Self-Organizing Map candidates, and selects a Self-Organizing Map candidate the average and the standard deviation of which are both minimum as the Self-Organizing Map.

5 5. An information processor according to claim 4, wherein, if there is no Self-Organizing Map candidate the average and the standard deviation of which are both minimum, said Self-Organizing Map creating means selects a Self-Organizing Map
10 candidate the average of which is minimum as the Self-Organizing Map.

6. An information processor according to one of claims 3-5, wherein said Self-Organizing Map creating means deletes a neuron which has never
15 become a winning neuron among neurons in the Self-Organizing Map that has been selected.

7. A state judging unit for judging a state of an object comprising:

20 a storage unit for storing individual separation models in the form of the plural of the Self-Organizing Maps, created one for each of the plurality of operation modes by an information processor defined one of claims 1-6;

 said detecting means; and

judging means for judging which operation mode
an operation of the object corresponds to based on
a relative distance between a detection data point
in 2n dimension corresponding to detection data
5 obtained by said detecting means in real time and
a winning neuron in each of said plural
Self-Organizing Maps.

8. A state judging unit according to claim
7, wherein said detecting means calculates the
10 relative distance by dividing the distance between
the detection data point obtained by said detecting
means in real time and the winning neuron in each
said Self-Organizing Map by the average of distances
of the winning neurons in the Self-Organizing Map
15 to the learning data point used in the process of
creating each said Self-Organizing Map in the
information processor.

9. A state judging unit according to claim
7 or 8, wherein said judging means judges that, if
20 the relative distance of one of said plural
Self-Organizing Maps is equal to or smaller than
a predetermined threshold value, the detection data
point conform with the one Self-Organizing Map, and
that, if the relative distance of said
25 Self-Organizing Map is larger than the threshold

value, the detection data point does not conform with said one Self-Organizing Map.

10. A diagnostic unit, including a state judging unit defined in one of claims 7-9, for
5 diagnosing the object, wherein the object is a machine including a construction machine, and the plural operation modes represent a particular operation performed by said machine.

11. An information processing method
10 comprising the steps of:
detecting a multiplicity of combinations of n parameter values, where n is a natural number, for each of a plurality of operation modes in which an object functions, which values vary with
15 operation; and

creating a Self-Organizing Map by using detection data, obtained on the basis of the multiple combinations of parameter values detected in said step of detecting, as learning data;

20 wherein, in said step of Self-Organizing-Map creating, a plurality of the Self-Organizing Maps, serving as individual separation models, are created one for each of the plurality of operation modes.

12. An information processing method

according to claim 11, further comprising the step
of, between said step of detecting and said step
of Self-Organizing-Map creating, calculating n
time-difference values by processing the n parameter
5 values detected in said step of detecting,

the Self-Organizing Map being created based
on $2n$ -dimensional data including the n parameter
values, which have been detected and which indicate
a momentary state of the object, and the n
10 time-difference values which have been calculated
using the n parameter values and which indicate a
variation in the momentary state of the object.

13. An information processing method
according to claim 11 or 12, wherein:

15 the multiple combinations of n parameter
values are detected in said step of detecting; and
said step of Self-Organizing-Map includes the
sub-steps of

creating a Self-Organizing Map candidate
20 by initially arranging a predetermined number of
neurons at random in a $2n$ -dimensional space,
carrying out training regarding a point of the
detection data in the $2n$ -dimensional space as a
learning data point and creating a Self-Organizing
25 Map candidate regarding a neuron having a minimum
distance to the learning data point as a winning

neuron, and

selecting, from two or more
Self-Organizing Map candidates created by carrying
out said step of creating a Self-Organizing Map
5 candidate a number of times, a Self-Organizing Map
candidate which has a characteristic closest to that
of the learning data as the Self-Organizing Map.

14. An information processing method
according to claim 13, wherein said step of
10 Self-Organizing-Map creating further includes a
sub-step of, after said sub-step of selecting a
Self-Organizing Map, deleting an idling neuron which
has never become a winning neuron among neurons in
the Self-Organizing Map that has been selected.

15 15. An information processing method
according to one of claims 11-14, wherein:
when a Self-Organizing Map for a new operation
mode of the object other than the plural operation
modes is added,

20 the n parameter values are detected by said
step of detecting while the object is functioning
in the new operation mode by said step of detecting;
and

a Self-Organizing Map for the new operation
25 mode is created regarding detection data based on

a multiplicity of combinations of the parameter values that have been detected as learning data by said step of Self-Organizing-Map creating.

16. A state judging method for judging which
5 operation mode an operation of the object
corresponds to using a plurality of Self-Organizing
Maps, serving as individual separation models and
created one for each of a plurality of operation
modes by an information processing method according
10 to one of claims 11-15, comprising the step of:
detecting the n parameter values that vary
with operation; and
judging which operation mode an operation of
the object corresponds to based on a relative
15 distance between a detection data point in a
 $2n$ -dimensional space corresponding to detection
data obtained in real time in said step of detecting
and a winning neuron in each of the plural
Self-Organizing Maps.

20 17. A state judging method according to claim
16, further comprising the step of, between said
step of detecting and said step of judging,
calculating n time-difference values by processing
the n parameter values detected in said step of
25 detecting,

the operation mode of the object is judged based on $2n$ -dimensional data including the n parameter values, which have been detected and which indicate a momentary state of the object, and the
5 n time-difference values, which have been processing the n parameter values detected in said step of detecting and which indicate a variation in the momentary state of the object, in said step of judging.

10 18. A state judging method according to claim 17, wherein, said step of judging comprising

obtaining the relative distance by dividing the distance between the detection data point obtained in real time in said step of detecting and
15 the winning neuron in the Self-Organizing Map by the average of distances of the winning neurons in each said Self-Organizing Map to the learning data point used in the process of creating the Self-Organizing Map carried out by the information
20 processor,

if the relative distance of each said the plural Self-Organizing Maps is equal to or smaller than a predetermined threshold value,

judging the detection data point to conform
25 with the last-named Self-Organizing Map, and

if the relative distance of each said

Self-Organizing Map is larger than the threshold value,

judging the detection data point not to conform with said one Self-Organizing Map.

5 19. A diagnosing method, including a state judging method defined in one of claims 16-18, for diagnosing the object wherein the object is a machine including a construction machine, and the plural operation modes represent a particular operation
10 performed by said machine.

 20. A diagnosing method according to claim 19, wherein, if there is no Self-Organizing Map conforming, the particular operation is judged to be an unknown mode or an abnormal mode in said step
15 of judging.